TU Delft

An interactive version of this poster can be found at https://mapfm-poster.jdonszelmann.nl

Matching in Multi-Agent Pathfinding using M*

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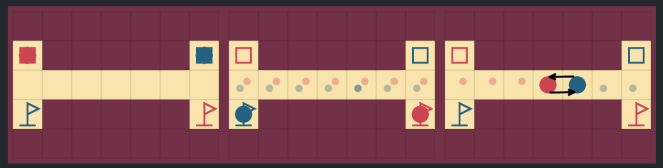
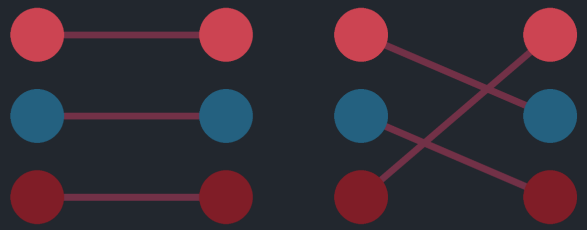
Multi-agent pathfinding



A start state | A goal state | An illegal action

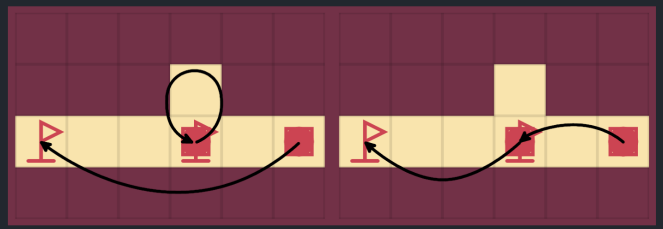
Multi agent pathfinding (MAPF) is finding collision-free paths for multiple agents.

Matching in MAPF



A trivial matching | A more complex matching

Grouping agents in MAPF into teams gives MAPFM, MAPF with matching. Agents travel to one their team's goals. An assignment from agents to goals is called a matching.

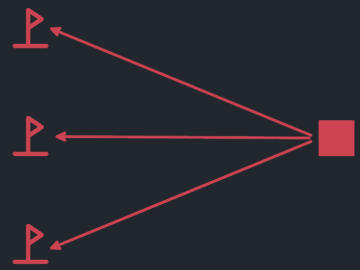


A possible matching | Another, shorter, matching

M*

- A complete and optimal algorithm to solve MAPF instances.
- Derived from A*.
- Tries to separate the planning of agents as much as possible.

Inmatching

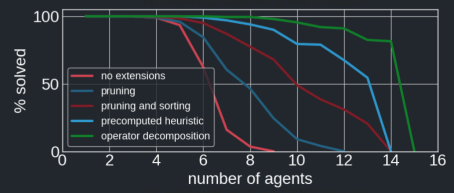


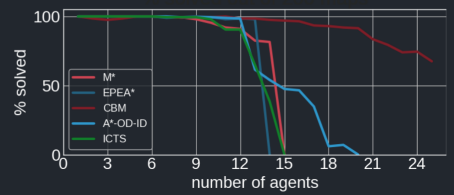
Inmatching evaluates all matchings simultaneously.

Prematching

Agents search a path to only one of their goals at a time. All possible assignments of agents to goals are considered.

Results





Graphs display percentage solved in 2 minutes out of 200 20x20 maps, 25% filled with obstacles. Agents are split over 3 teams. All maps are guaranteed to be theoretically solvable.

Conclusion

- Prematching is generally preferable to Inmatching.
- Several extensions to M* and to prematching can improve the performance of M*.
- The performance of M* is comparable to that of other A* derived algorithms.

Complete explanations, results and conclusions can be found at https://mapf-poster.jdonszelmann.nl/paper.